<u>**AMENDMENTS TO THE CLAIMS:**</u>

This listing of claims will replace all prior versions, and listings, of claims in the application:

<u>**LISTING OF CLAIMS:**</u>

1-10. (Cancelled)

11.   (New) A cruise control device for speed control in a motor vehicle having a radar sensor, the speed control being a constant-distance control if at least one preceding vehicle is detected by the radar sensor, the speed control being a constant-speed regulation if no preceding vehicle is detected by the radar sensor, the device comprising:

means for receiving measured object values for detected objects;

a computing device for determining an acceleration gradient for each measured value of each object and for adding-up the acceleration gradients of the measured values for each object; and

means for outputting the added-up acceleration gradient for an object selected as a target object.

12.   (New) The device according to claim 11, wherein the means for receiving includes an input circuit, and the measured values include at least one or a combination of the following input quantities:

an object distance,

a relative speed of the object,

a longitudinal acceleration of the object,

a transverse offset of the object,

a transverse speed of the object, and

a transverse acceleration of the object.

13.   (New) The device according to claim 11,

wherein the acceleration gradient for each measured value of each object is determined using a table lookup device.

14.   (New) The device according to claim 11,

wherein a sum of the acceleration gradients for each object does not exceed a predefined limiting value which is output as a maximum.

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15. (New) The device according to claim 11,

wherein a vehicle immediately preceding a host vehicle is selected as a target object.

16. (New) A method for speed control in a motor vehicle having a radar sensor, the speed control being a constant-distance regulation if at least one preceding vehicle is detected by the radar sensor, the speed control being a constant-speed regulation if no preceding vehicle is detected by the radar sensor, the method comprising:

supplying measured object values for detected objects to a cruise control;

determining an acceleration gradient for each measured value of each object, using a computing device;

adding-up the acceleration gradients of the measured values for each object; and

outputting the added-up acceleration gradient for an object selected as a target object.

17. (New) The method according to claim 16, wherein the measured values include at least one or a combination of the following input quantities:

an object distance,

a relative speed of the object,

a longitudinal acceleration of the object,

a transverse offset of the object,

a transverse speed of the object, and

a transverse acceleration of the object.

18. (New) The method according to claim 16,

wherein the acceleration gradient for each measured value of each object is determined using a table lookup device.

19. (New) The method according to claim 16,

wherein a sum of the acceleration gradients for each object does not exceed a predefined limiting value which is output as a maximum by the cruise control.

20. (New) The method according to claim 16,

wherein a vehicle immediately preceding a host vehicle is selected as the target object.